

FIG. 1

TRACKING ERROR SIGNAL ANALYSIS

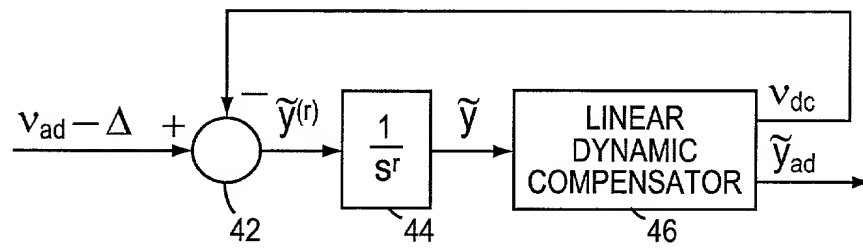


FIG. 2

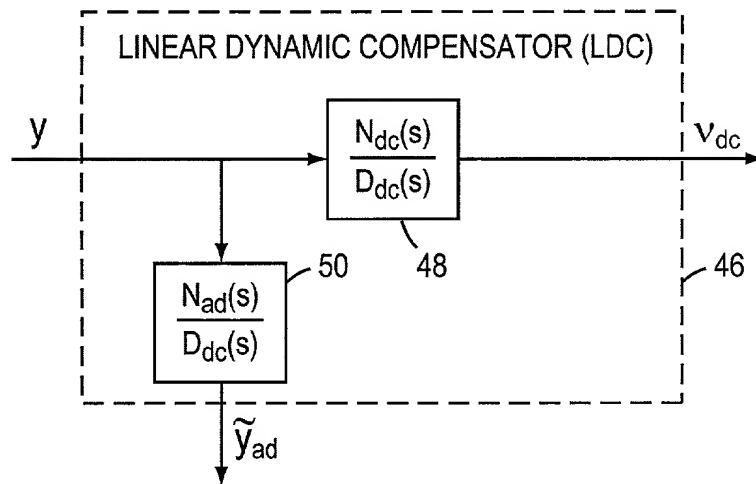


FIG. 3

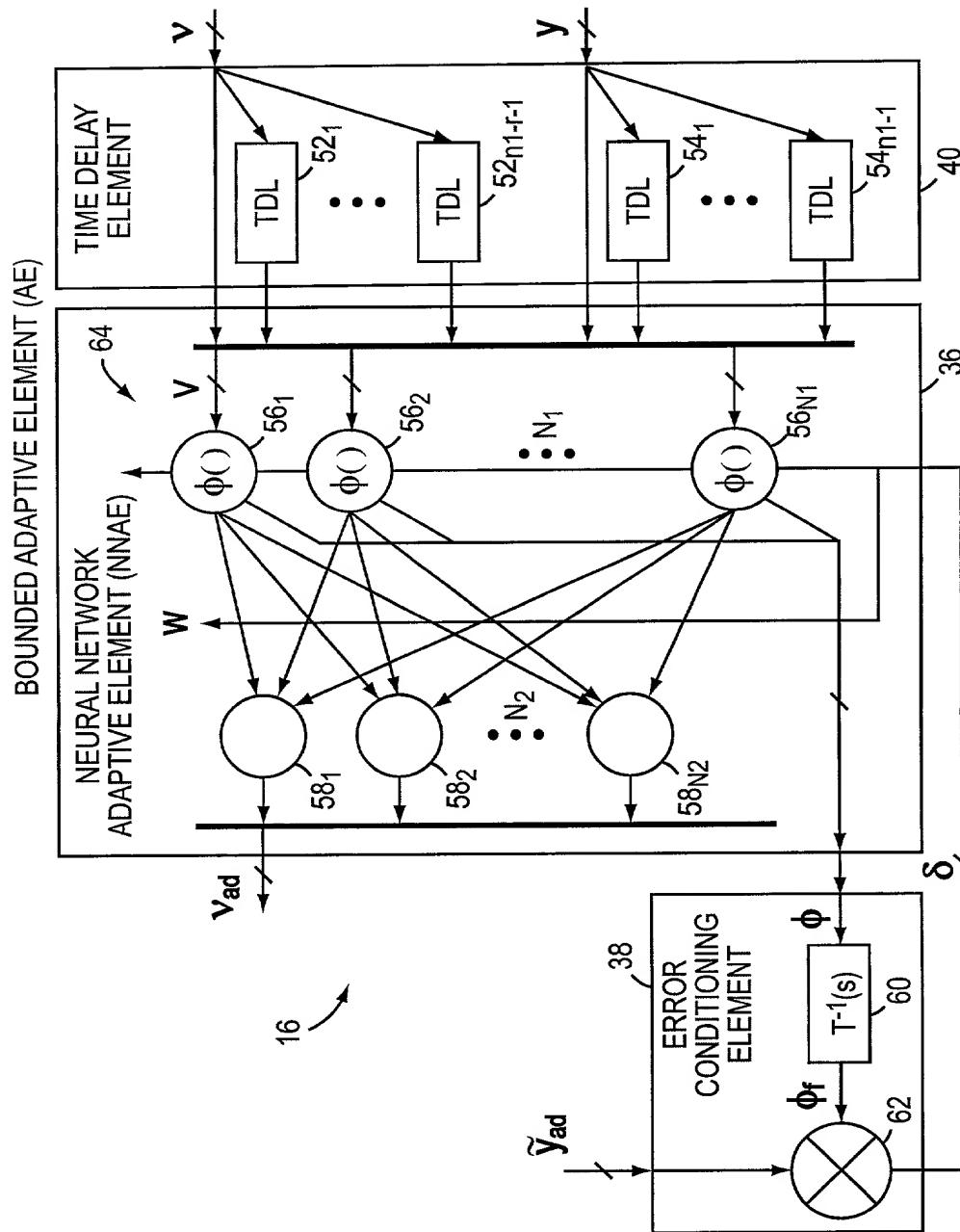


FIG. 4

PROCESSOR-BASED ADAPTIVE CONTROL SYSTEM USING DIRECT OUTPUT FEEDBACK

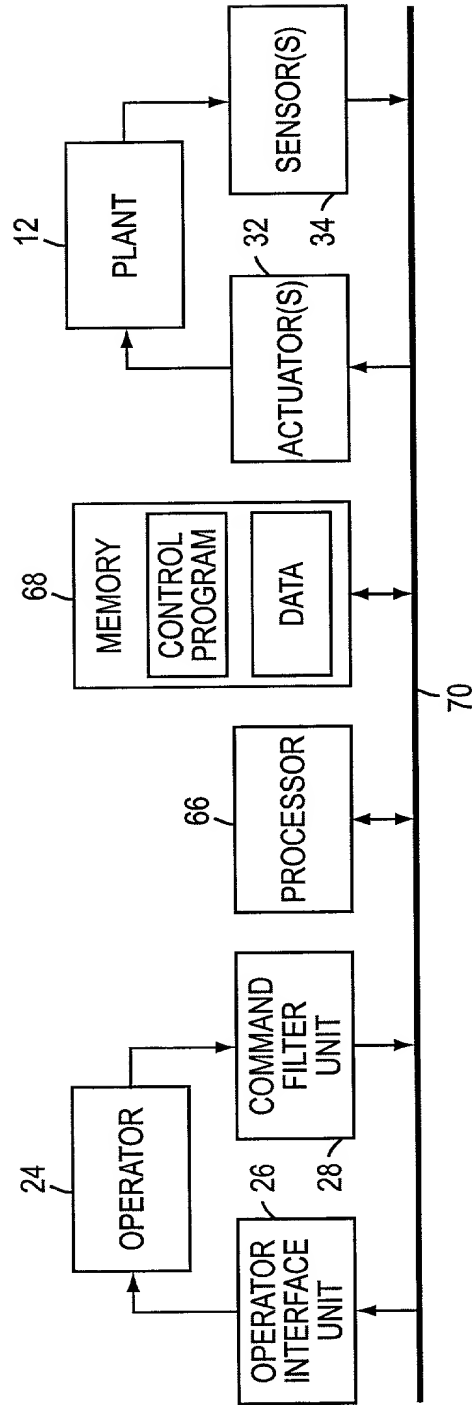


FIG. 5

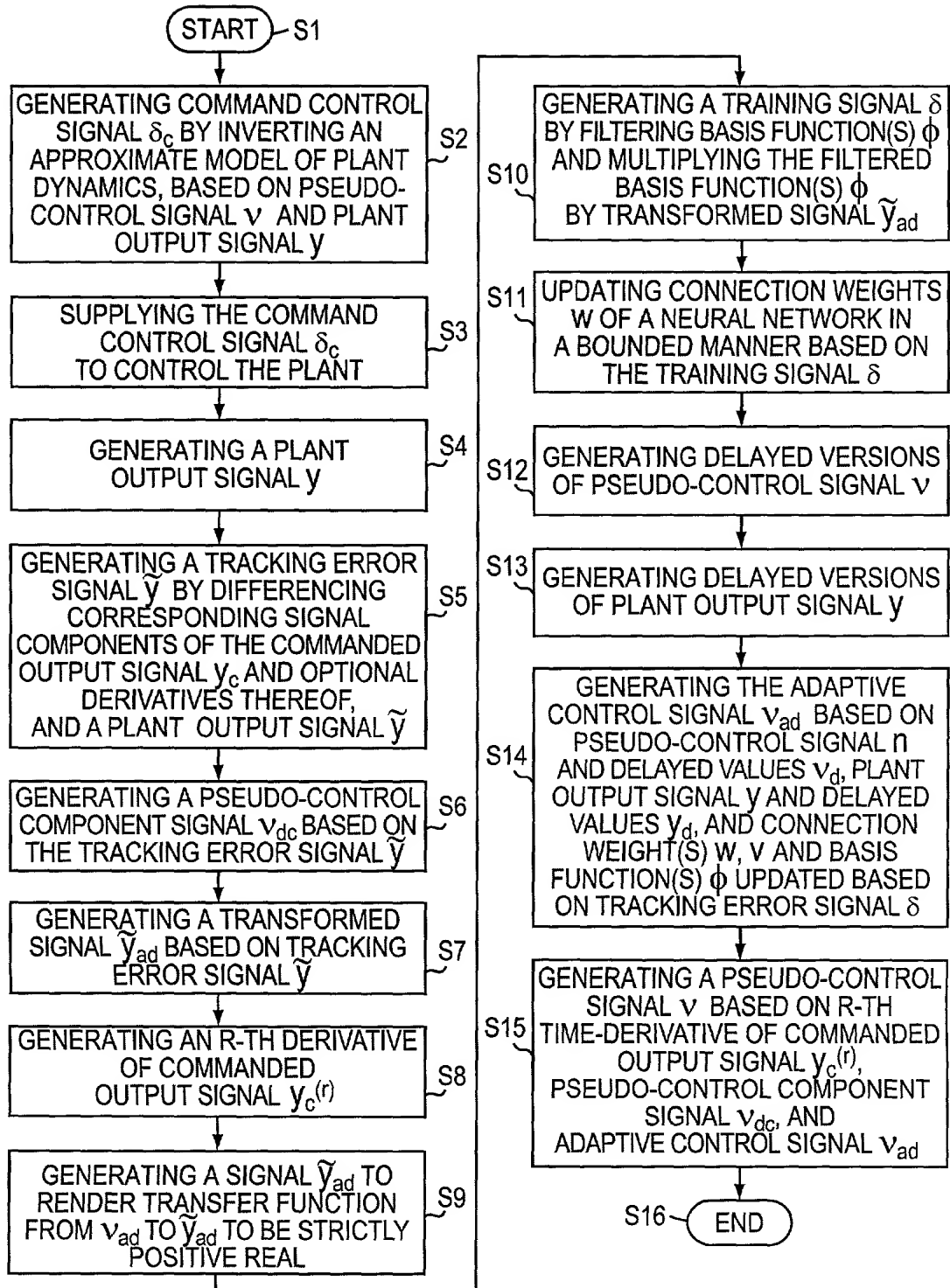
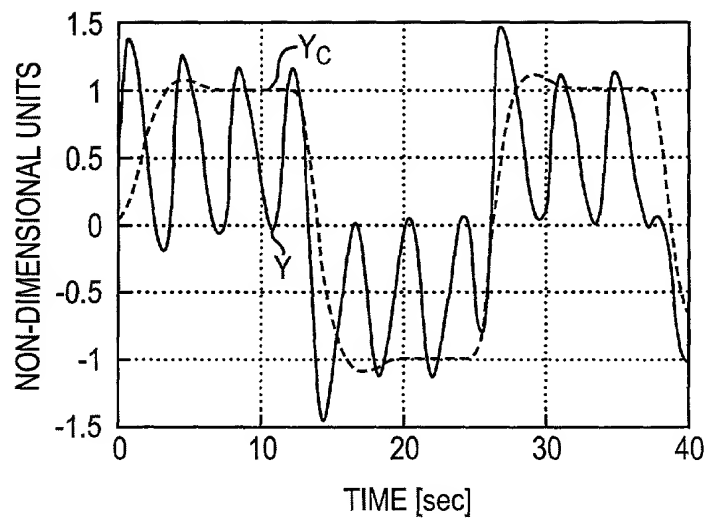


FIG. 6

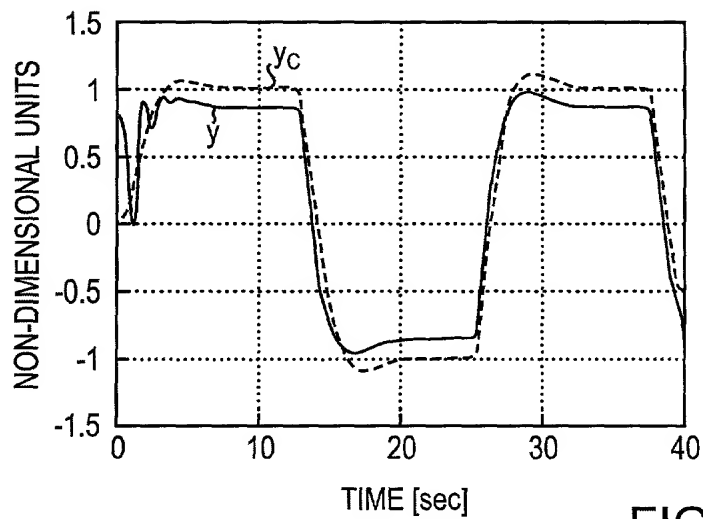
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SYSTEM WITHOUT UNMODELLED DYNAMICS:
RESPONSE WITH LINEAR COMPENSATOR

FIG. 7

SYSTEM WITHOUT UNMODELLED DYNAMICS AND NN CONTROLLER



(a) SYSTEM TRACKING

FIG. 8A

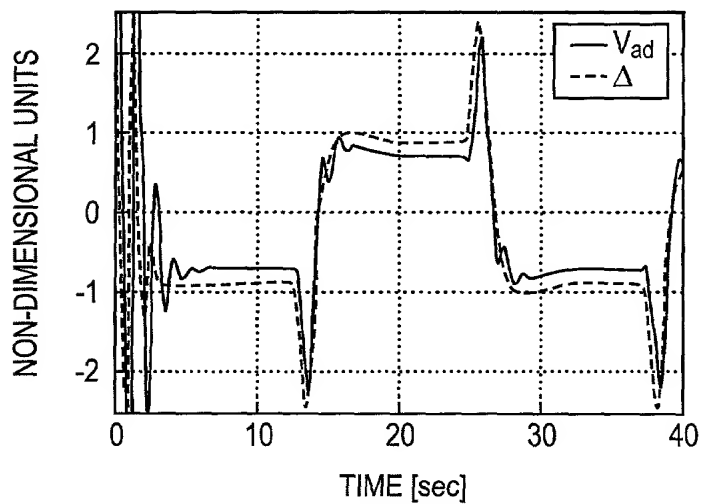
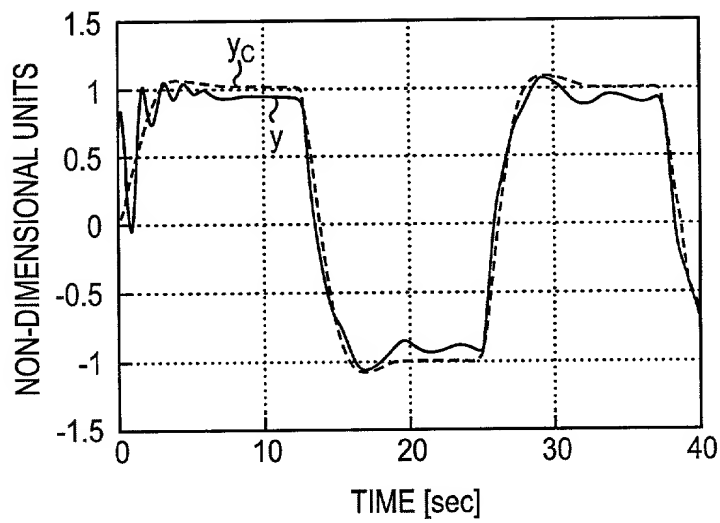
(b) NN OUTPUT V_{ad} AND INVERSION ERROR Δ

FIG. 8B

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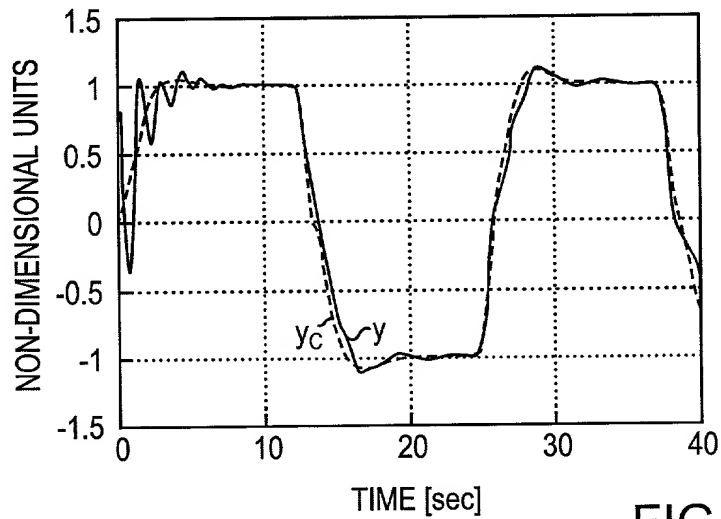


SYSTEM WITH UNMODELLED DYNAMICS:
RESPONSE WITH NN CONTROLLER

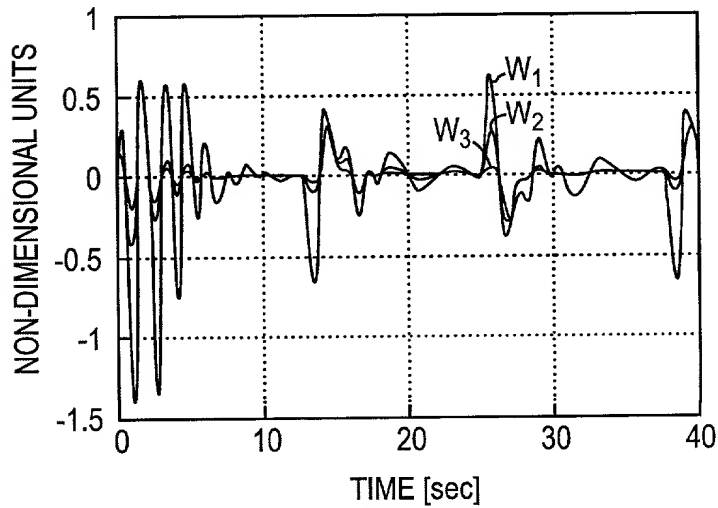
FIG. 9

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SYSTEM WITH UNMODELLED DYNAMICS:
RESPONSE WITH NN CONTROLLER AND LINEAR COMPENSATOR



(a) SYSTEM TRACKING



(b) NN WEIGHT HISTORY